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### LOKI WIND CORRECTION COMPUTER

by

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and

WIND STUDIES FOR LOKI

by

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### Annual Summary

The work performed during the first year of the LOKI Wind Correction Computer development program has fallen into four phases, described in detail in the North American Instruments, Inc. Quarterly Report series.

In the first phase, the effect of an arbitrary wind distribution on the LOKI trajectory during boost was determined by an impulse response method, and a function was derived relating burnout deviation of flight path with the distributed wind along the boost trajectory. Complete details of the derivation are included in the First Quarterly Report, Ref. 5. To verify the theoretical influence function, arrangements have been made for an experimental comparison at White Sands Proving Ground. The Signal Corps is erecting ten poles instrumented with enemometers at the launching site of the Small Missiles Range, for this purpose. This system is expected to be in operation within the next few months.

In the second phase, the wind influence function was then applied to arbitrary and observed wind distributions with a view to establishing the basis for a practical field wind measuring system to transmit information to a computer which could perform an aiming correction. The studies indicated the feasibility of a correction method

based on a linear relationship between burnout deviation and wind, suitably measured, at a limited number of fixed stations. This work is described in the Second Quarterly Report. The conclusions are supported by further studies included in this report.

To supplement immediately the wind data obtained from the literature, which extend up to 250 feet altitude (50% of the burnout deviation effect), with measurements extending to 1,000 feet of altitude (94% of the burnout deviation effect), a balloon-borne hot wire anemometer system was constructed and put into field operation, data being gathered in the Mojave Desert at El Mirage Airport, and at White Sands Proving Ground at the Small Missiles Range. The equipment is described in the Third Quarterly Report. A more complete program involving space and time variations of wind within a volume significant in the general rocket aiming problem has been set up under the sponsorship of the Signal Corps. The system involves the erection of a number of high towers and the operation of a complex data recording system. It is expected that data will become available from this project within the next year.

At the outset of the computer development program the possible need was recognized for an anemometer capable of fast response, to provide orthogonal wind components in terms of electrical outputs. No such instrument was available and a design was undertaken based on the drag force exerted by the wind stream on a transverse cylinder.

The development of this 2-component anemometer constituted the thirdphase and extended through most of the year and resulted in a prototype unit suitable for field operation. Details on the design and wind tunnel testing of the anemometer are contained in the Third Quarterly Report.

The final phase of the past year's work, described in this report, has been the design of a complete wind correction computer system based on the influence function and the results of the wind studies.

### Acknowledgment

We wish to acknowledge helpful discussions, held during the preparation of this report, with members of the Beli Telephone Laboratories on the subjects of Computer Geometry and Components.

### PART I

### WIND CORRECTION COMPUTER

### Introduction

The purpose of the computer which is the subject of this report is to correct the aim of a rocket launcher (in both azimuth and elevation) for the wind forces experienced by the rocket during its burning period. As a result of a statictical study of winds within a few hundred feet of the ground, it is believed that the effect of these so-called surface winds upon the rocket trajectory can be expressed by a linear relation involving the two horizontal wind components at or near the rocket launcher. The details of the wind structure study are presented in this report and in an earlier one, Ref. 1, and the anemometer used in both the wind study and in the wind correction computer has been described earlier, Ref. 2.

The angular deviation at the end of burning due to wind normal to the trajectory, a-mounts to approximately one mil (thousandth radian) per mile-per-hour; it is not expected that rocket launching will be attempted in winds above 40 miles per hour. Current experimental rocket dispersions amount to 8 mils (linear standard deviation), and a wind correction standard deviation of about 2 miles thus appears acceptable.

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### Operating Principle of Computer

The wind correction computer corrects the point of aim of the rocket launcher for deviations from its intended trajectory due to wind. The corrections are made in both azimuth and elevation; both corrections are inserted as rotations of the shafts of differential selsyns interposed in the transmission lines between the main fire control director (M33) and the launcher. The wind correction computer is physically separate from the main fire control director and may be remote from it.

The wind data received from the anemometer is in the form of two amplitude-modulated 3000 cps signals; the amplitudes are proportional to  $V^2\cos\Theta$  and  $V^2\sin\Theta$ , the northerly and westerly components of the square of the wind velocity; the wind is assumed to lie in the horizontal plane. Here V is the wind velocity and  $\Theta$  is the wind vector heading angle measure is counter-clockwise relative to true north. Because the anemometers do not deliver actual velocity components, the computer must convert  $V^2\cos\Theta$  and  $V^2\sin\Theta$  into  $V\cos\Theta$  and  $V\sin\Theta$ , respectively. Secondly, if the anemometer is fixed in orientation, (i.e., not slaved in azimuth to the launcher), it is necessary to carry out the vector rotations which resolve the northerly and westerly wind components into down-range and cross-range winds; this is achieved in the computer by sine and cosine potentiometers and operational adders. If A is the azimuth

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angle of the launcher, the desired quantities are:

$$V\cos(\Theta - A) = (V\cos\Theta) \cos A + (V\sin\Theta) \sin A$$
 (1)

$$V\sin(\Theta - A) = -(V\cos\Theta) \sin A + (V\sin\Theta) \cos A$$
 (2)

We may replace (€ -A) by Ø, the wind heading relative to the launcher azimuth.

Since only those wind components normal to the trajectory are effective in producing deflections of the trajectory, the angular rotation due to wind may be resolved into two angular rotations normal to the trajectory. The horizontal and vertical angular deviations  $W_h$  and  $W_{V^t}$  respectively, may be obtained by the geometric relations, illustrated in Fig. 1. Because of the smallness of the angular deviation, the deviation resolves in the same manner as the wind force which causes it. The incremental angles are:

$$W_{h} = KV \sin Q \tag{3}$$

$$W_v = KV \cos \emptyset$$
 sinE (4)

where E is the corrected angle of launcher elevation and K is the influence coefficient relating wind (in mph) to angular deviation (in mils).

It should be remembered that the deviations are angular and the incremental vectors,  $W_n$ ,  $W_h$ , and  $W_v$  are chords of a unit sphere. Fig. 2 illustrates the spherical trigonometric relations utilized in deriving the wind corrections in azimuth and elevation.

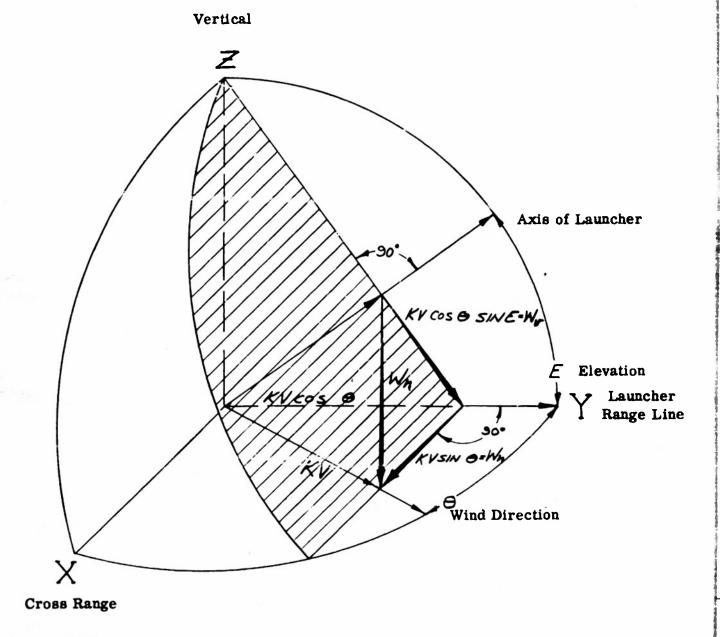


FIG. 1 RESOLUTION OF WIND VECTOR OR ANGULAR DEVIATION

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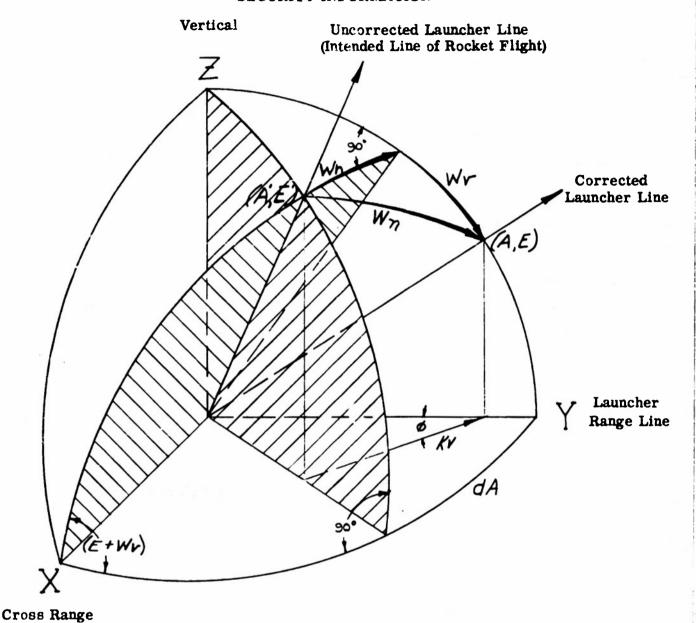


FIG. 2 RESOLUTION OF ANGULAR DEVIATION DUE TO WIND INTO AZIMUTH (A) AND ELEVATION (E) CORRECTIONS. PRIMED QUANTITIES ARE UNCORRECTED OR "AIM-POINT" VALUES.

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By the law of sines, one may write

$$\sin dA = \sin W_h/\cos E' \tag{5}$$

The quantity sin Wh may be replaced by Wh to within one part in 4,000; sin dA cannot be replaced by dA because dA may be as great as 560 mils; thus the equation for dA may be written:

$$\sin dA = W_h \sec E'$$
 (6)

The correction in elevation, dE, may be written by a second application of the law of sines as:

$$\sin (E + W_v) = \sin E'/\cos W_h \tag{7}$$

We shall want the expression in a form not involving E, so we substitute

$$\mathbf{E} = \mathbf{E}' \mathbf{\phi} \mathbf{d} \mathbf{E}$$
 (8)

with the result:

$$dE = -W_v + \frac{w_h^2}{2} tan E'$$
 (9)

In writing Equation (9), we have made use of the approximations:

$$\cos (dE + W_V) \neq 1$$
 0.3% (10)

$$\sin (dE + W_V) \leq (dE + W_V) \qquad 0.1\% \tag{11}$$

$$\sin (dE + W_v) \doteq (dE + W_v)$$
 0.1% (11)  
 $\cos W_h \doteq 1 - \frac{W_h^2}{2}$  10<sup>-5</sup>% (12)

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Equations (3), (4), (6), and (9) provide the mathematical basis for the computation of wind corrections. Equation (4) involves the angle E while all other relations involve E'.

If we denote

$$W_{V}^{1} = KV \cos \phi \sin E^{1}$$
 (13)

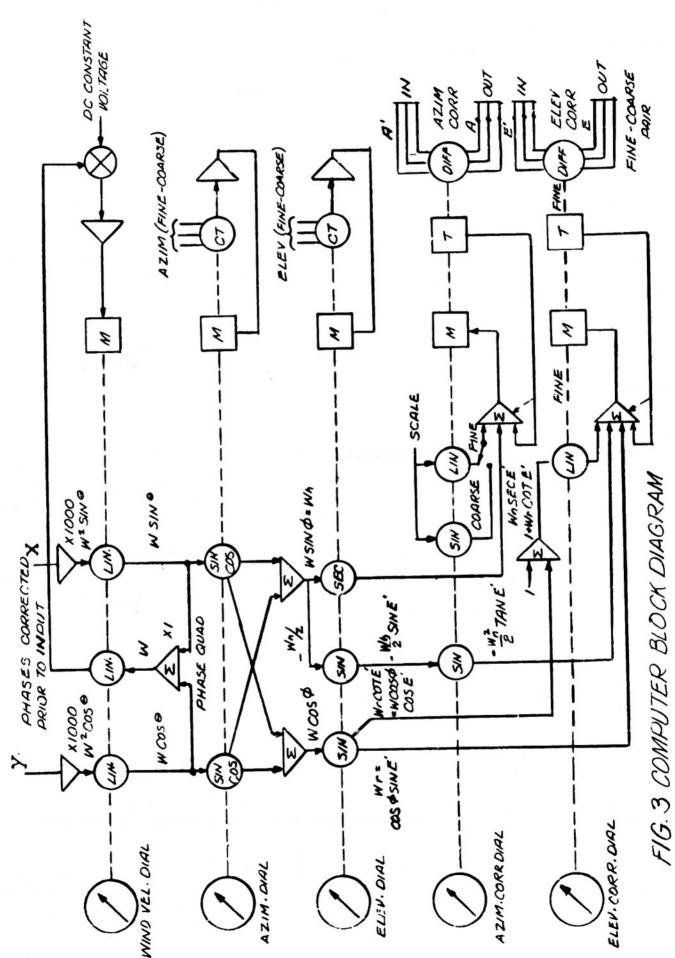
then 
$$(1 + W'_{v} \cot E') dE = -W'_{v} + \frac{W_{h}^{2}}{2} \tan E'$$
 (14)

Because of the small magnitude of W'<sub>V</sub>, neglect of the term W'<sub>V</sub> cot E' causes an error of less than 4% in dE. Hence, to within 1.6 mils, Equation (9) may be replaced by

$$dE = -W'_{\nabla} + \frac{W_h^2}{2} \quad tan E'$$
 (15)

the corrected elevation, E, does not appear in any of the computer relations and no servo shaft positioning device need be provided for it. If desirable, the computer can be arranged to avoid this slight error. Fig. 3 indicates a solution utilizing Equation (14). Computer Block Diagram

Fig. 3 presents a block diagram of the wind correction computer. The five horizontal dashed lines represent mechanical shafts, positioned by servomotors on the right; several linear or functional potentiometers are placed on each shaft; indicating dials (and selsyn or potentiometer transmitters, if required) are on the left side of the diagram.



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The manner in which the computer executes the mathematical relations may be seen fairly readily. The two anemeometer component aignals  $W^2 \sin \theta$  and  $W^2 \cos \theta$ , are amplified to suitable level and introduced at the top of Fig. 3. The three linear potentiometers and the quadrature superposition unit are used for extracting the square root of  $V^2$  and dividing each of the input signals to yield  $W \cos \theta$  and  $W \sin \theta$ . These signals are combined by means of the azimuth sine-cosine potentiometers and subsequent adding amplifiers to produce the components of the correction relative to the instantaneous launcher heading,  $W \cos \theta$  and  $W \sin \theta$ .

Several functional potentiometers are employed to modulate the V cos Ø and V sin Ø signals by sin E', cos E', and Sec E'; the outputs from these functional potentiometers are combined in several ways by adding amplifiers and the resulting signals are balanced by output servos against the signals derived from other potentiometers mounted on the output shafts.

### Square-Root Techniques

The potentiometer cascade utilized in the computer schematic of Fig. 3 is rather simple in principle, but may lead to significant dynamic error in operation due to the alowaeas of the servo-balancing as compared to wind fluctuations. An analysis of the dynamic error due to this cause has not yet been carried out; however, it is apparent that the error

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may amount to several percent unless the input signals are damped to correspond to the servo capabilities.

Damping may be achieved by means of an orifice in the anemometer (up to about 15 seconds time constant) or by filter networks placed in d. c. sections of the computer; experimentally, the latter method is more appealing because of the possibility of switching damping values. However, it is convenient to avoid the troubles of d. c. amplification in the computer by using the 3000 cps signals throughout; this favors mechanical damping. To lessen the importance of this controversy, it is contemplated to make the experimental computer convertible insofar as possible from a. c. to d. c. signal operation; this is the reason reactive resolvers are not used. If d. c. operation is employed, a. c. signals are none the less required through the quadrature circuits, and the rectification must take place after the square root has been extracted.

To eliminate the possible source of dynamic error in square rooting, two non-servo-square-root circuits have been investigated. One type of square-rooter utilizes the non-linear properties of Thyrite, while a second type employs suppressor controlled pentodes in a feedback circuit to extract the square root; simplified breadboard computers have been built utilizing both approaches. The two methods of square rooting are treated further in the following section.

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### Thyrite Type Computer

The computer utilizing Thyrite as a square root extracting device combines the signals  $V^2\cos\theta$  and  $V^2\sin\theta$  in phase quadrature to produce a signal of amplitude  $V^2$ . The Thyrite square root extractor delivers d. c. voltages proportional to +|V| and -|V|, which are applied to the two potentiometers. The output angular positions representing the azimuth and elevation corrections are positioned by servomechanisms effecting the following relations:

$$|V| \sin \Delta A = KV^2 \sin \emptyset \sec E'$$
 (16)

$$|V| \sin \Delta E = KV^2 \cos \emptyset \sin E'$$
 (17)

The computer requires the solution for which  $|V| \not\equiv O$ ; for this reason |V| is constrained to be significantly greater than zero at all times, regardless of wind. The use of a variable voltage |V| across the servo potentiometers leads to a system in which the servo loop gain is variable; as is well known, this situation is usually conducive to instability under some of the desired operating conditions. This situation might be tolerated in this mode of operation because of the convenience and economy of effecting both the square root extraction and the output positioning with the same servo.

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### Thyrite Characteristics

The non-linear characteristics of Thyrite, a material manufactured by the General Electric Company for use in lightning arrestors, are demonstrated by the plot of Fig. 4; the graph shows the voltage across a small Thyrite element as a function of the current passing through it. The slight departure from the desired square-root dependence is almost entirely corrected by the use of a trimming resistor, in this case about 300 ohms.

A very simple Thyrite driver circuit was tried, which requires only moderate voltages; the circuit is shown in Fig. 5 and its performance is represented by Fig. 7.

The 5% accuracy achieved in this trial circuit can undoubtedly be improved to correspond to the 2-3% result of the Thyrite alone.

### Suppressor Type Computer

To overcome the necessity for d.c. servo amplification and to avoid the hazards of variable servo-loop gain, some tests have been made of square root extraction by means of successive suppressor controlled variable gain amplification stages. The Suppressor Type Computer utilizes this type of circuit for square root extraction. The computer shown in Fig. 3 is different from the Suppressor Type only in its use of two successive potentiometer stages for root extraction rather than suppressor controlled amplification

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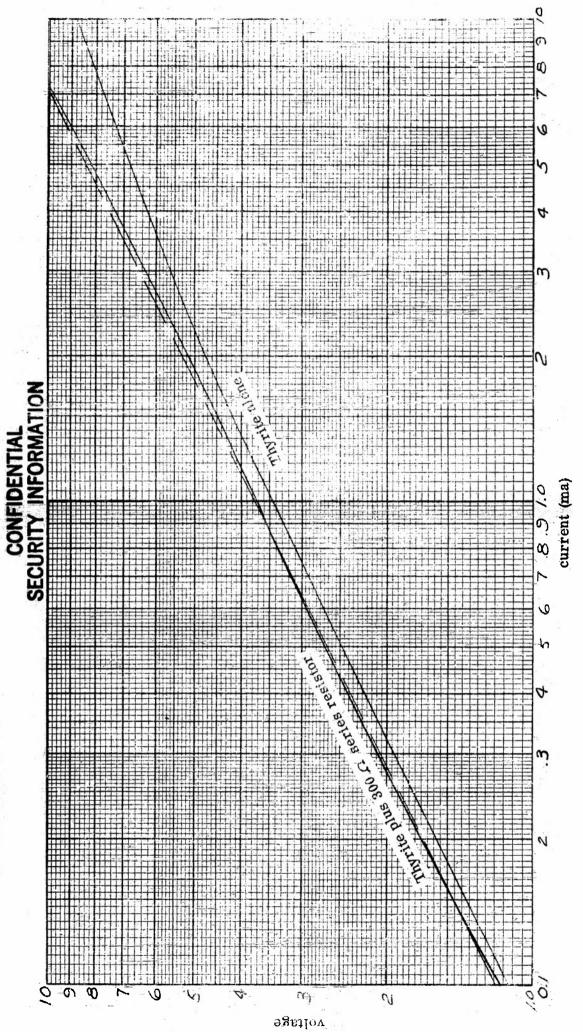


FIG. 4 THYRITE CHARACTERISTICS

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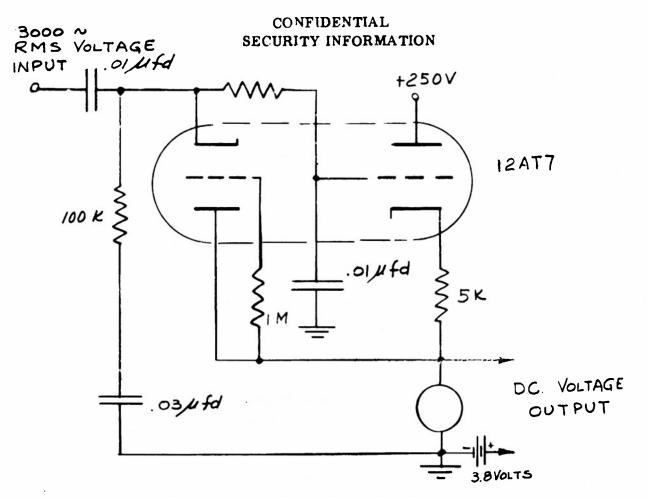


FIG. 5 THYRITE DRIVER CIRCUIT

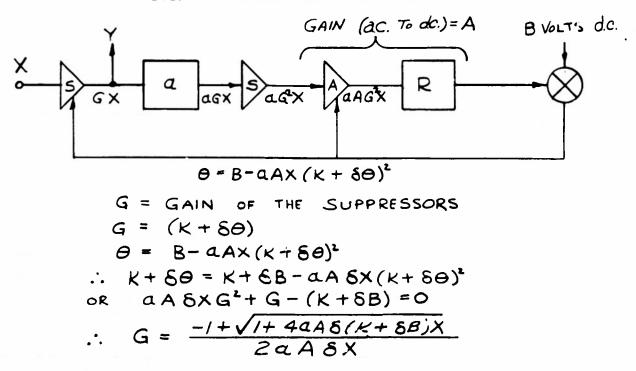


FIG. 6 PRINCIPLE OF SQUARE ROOT EXTRACTION WITH SUPPRESSOR AMPLIFIERS

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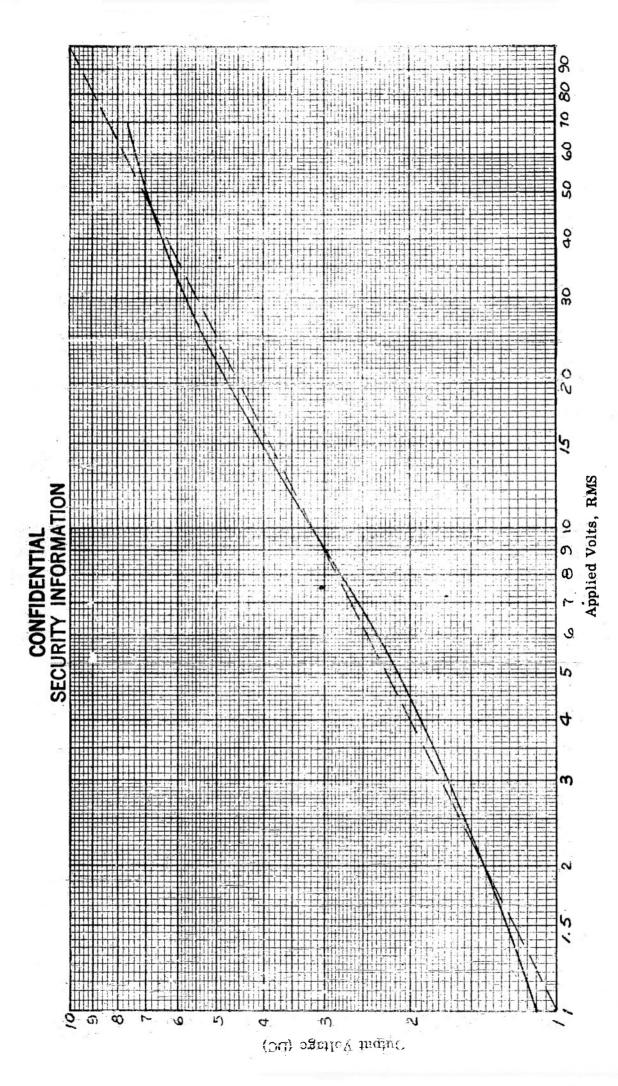


FIG. 7 THYRITE DRIVER PERFORMANCE

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stages. This type of computer, whether it uses suppressor amplifiers or potentiometers for root extraction, has the advantage that no d. c. amplification is required; only simple phase sensitive rectification is required at the output stages of the servo amplifiers.

Suppressor Amplifier Root Extraction

The principle of square root extraction with a feedback circuit incorporating suppressor amplifiers is outlined in Fig. 6. The amplifiers labelled "S" are stages employing, for example, 6AS6 pentodes in which the gain can be controlled readily by the suppressor grid bias. Assuming linear characteristics in the range of operation, the gain of each stage is

$$G = \frac{-1 + \sqrt{1 + 4(K + 5B) 5 \text{ AAx}}}{28\text{A5x}}$$
 (18)

where K is the gain of the suppressor amplifier at zero bias,  $\delta$  is the change of gain per volt of bias, aA is the constant portion of the loop gain (subsequent to the suppressor amplifiers and including the rectification), and X is the input signal (RMS volts). A has the units d.c. volts per RMS volt. B is the d.c. voltage that is compared with the output of the rectifier. The output of the first suppressor stage is, therefore:

$$Y = GX \approx \sqrt{\frac{(K + \delta B)x}{aA}} \left(1 + \frac{1}{8aA \delta (K + \delta B)x}\right) - \frac{1}{2aA \delta}$$
(19)

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Typical values of the parameters are:

K = 65

 $\delta = 6.2 \text{ per volt}$ 

8A = 67

B = 50 volts d. c.

The calculated behavior of this system shows an error equivalent to less than 0.5 mil; experimental results are not yet available.

The suppressor amplifier square root scheme assumes that the gains of the several suppressor amplifiers vary in unison; to the extent that this is required it constitutes a strong reason against the use of the scheme in an operation computer. However, it can be shown that compensation for differences in tube characteristics can be achieved in large measure by interchanging tubes so that, for example

$$G_2 = G_1 \left[ 1 + \ll \langle x \rangle \right], \propto \langle x \rangle \ge \overline{0}$$
 (20)

and adjusting the loop gain so that, approximately

$$G_1G_2 \times - C \left[1 + \infty(x)\right] \tag{21}$$

PART II -12-

### WIND STUDIES FOR LOKI

### Introduction

In an earlier report of this project, Ref. 1, a series of vertical wind profiles was studied to determine the feasibility of a wind correction computer for LOKI, based on a linear relationship between burnout deviation and wind at a selected level. Only a limited number of wind profiles was involved in the comparison. However, significant correlations were found between computed burnout deviation and corresponding single level wind measurements. The effects of altitude and smoothing were examined, comparisons being made with wind level and time averaged velocity as parameters.

The wind data used was that of Sherlock and Stout for winter storms in Michigan, Refs. 3 and 4, and was obtained with a 250-foot tower instrumented with fast response pressure plate anemometers at 25-foot intervals. It was learned from the authors that the published information was only a small part of a large total which had been reduced from the original oscillograph records to punched IBM cards. Several thousand of these cards were available; duplicates were obtained and these were processed by the Los Angeles IBM Service Bureau to extend the initial investigation. The results of the IBM computations which are presented in this report, confirm the initial findings and permit a selection of optimum altitude and time average through the use of a wider range

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of these parameters. Also comparisons were made using combinations of wind values at two altitudes. These appear to offer little improvement over appropriately smoothed single altitude winds at levels above 50 feet.

### Discussion

The function relating LOKI deviation at burnout with the distributed wind along the trajectory was derived in Ref. 5 and is shown in Fig. 8 as a plot between wind influence coefficient (deviation of flight path at burnout from direction at launching per unit cross-wind per unit distance increment along trajectory) and distance of rocket from launcher. The cumulative effect of a constant crosswind during boost is shown in Fig. 9. The total deviation for unit crosswind is .8 mil, 50% being accumulated in the first 200 feet of trajectory and 95% in the first 1,000 feet.

The results of the preliminary investigation are tabulated in Fig. 10 from Ref. 1. The burnout deviations for 150 cases were calculated by integrating the wind observations weighted with the influence function and apply to a theoretical vertical shot. Since the wind observations extend to 250 feet, the deviation is about 50% of the total that would be obtained if the integration were carried to burnout.

The work discussed in this report extends the number of cases from 150 to 4,000 using the same altitudes, 25, 50, 100, and 150 feet with the addition of the mean of the 25 and

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Wind	Wind Deviation at Burnout			4-Second Average Wind Deviation at Burnout				
Measurement Level		Correlation Coefficient	Deviation Spread for 90% Obs. mils	Regression Line Slope mils/mph	Correlation Coefficient	Deviation Spread for 90% Obs. mils		
25	. 544	. 802	<u>÷</u> 4. 9	. 582	. 823	± 4. 4		
50	. 399	. 805	± 4.7	. 419	. 836	÷ 3. 9		
100	. 488	. 901	± 3.3	. 491	. 896	<u>+</u> 3.2		
150	. 441	. 939	<u>+</u> 2. 6	. 446	. 945	<u>±</u> 2.3		

FIG. 10 SUMMARY OF RESULTS OF PRELIMINARY WIND STUDIES FOR LOKI (Ref. 1)

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100-foot winds, and the mean of the 50 and 150-foot winds. Also the 1 and 4-second wind averages in the initial survey are augmented by the 2 and 8-second averages.

The basic wind data as received from the University of Michigan, was in the form of punched IBM cards and apply to the storms of Apr. 28, 1931 and Jan. 19, 1933. All records were originally taken continuously on oscillograph paper, information being transferred from these records onto the cards. The card code identification is shown in Fig. 11.

The first vertical column at the left identifies the run number. Each storm sample was divided into runs of various lengths, the oscillograph being operated intermittently to record during periods of major gust activity. Many runs were found to be broken, due to missing card data, and in order to provide continuous time sequences for analysis, these runs were broken into sub-groups and labelled episodes.

The second column identifies the length of time interval overwhich the velocity observations were averaged. Averages from 1/4 sec. to 10 sec. were available; however, the averages used in all computations were based on the 1-second cards.

The third column shows the number of seconds after the start of a run, and columns 5 to 16 show the wind speeds in miles per hour at each of the observation stations. The ten stations on the tower were at 25-foot intervals and are identified by numbers 1 to 10 reading from the bottom.

			27											
				11										Jt
			10	32.2	33.5	33.2	33.8	33. 5	33.8	34.1	33.8	36.8		
			(6)											
	-		8	27.8	30.1	31.0	31.9	32.8	36.0	33.3	32.2	31.6		
	Ħ		7	27.9	29.4	29.0						28.2		
	Velocity in MPH	n Numb	9	28.7	31.1	29.7						27.5		
		Statio	5	25.1	25.4	26.8						29.4		
				000	200	200						80		
			8	23.9	23.9	etc.						29.3		
			2	25.3	24.4	etc.						24.9		
				22. 5	22.9	etc.						20.4	etc.	
8	Card Number 4 Int. 1/4 Sec.			1	64	က	4	-	89	က	4	-		
Code Identification	Seconds after start of Run			8	8	000	900	100	100	8	901	250		
ij	Time = 1/4 8ec	·.		1	-	-	-	-	-	-	-	<b>—</b>		
	Run Number			320	885	825	925	925	828	625	828	925	7	
•		_				_								

FIG. 11 IBM CARD IDENTIFICATION CODE

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Statistical comparisons were made for each run separately to determine the correlation, coefficient, the slope of the burnout deviation vs. wind speed regression line and the 90% confidence limits for the burnout deviation. In calculating the burnout deviation sequences, the wind values at each altitude were assumed to describe the wind extending from the adjacent lower altitude using weighting factors determined from the influence function. The results as tabulated by IBM are presented in the Appendix.

The formulae used in the computations follow:

Correlation coefficient, 
$$r = \frac{N\Sigma \delta A - \Sigma A \Sigma \delta}{\left[N\Sigma A^2 - (\Sigma A)^2\right] \left[N\Sigma \delta^2 - (\Sigma \delta)^2\right]^{\frac{1}{2}}}$$

90% Confidence Limits,  $Sy_{90} = \frac{1.65 \left[N\Sigma \delta^2 - (\Sigma \delta)^2\right]^{\frac{1}{2}}}{N}$ 

Regression Line Slope, b = 
$$\frac{N\Sigma\delta A - \Sigma\delta\Sigma A}{N\Sigma\delta^2 - (\Sigma\delta)^2}$$

$$\bar{\delta} = \frac{\Sigma\delta}{N}$$
(Regression Line passes through  $\bar{A}$ ,  $\bar{\delta}$ )

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Mean Wind A jmpk = 
$$\frac{1}{m} \sum_{d=m+1}^{k} \bigvee_{i \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{j \in K} \bigcap_{j \in K} \bigcap_{j \in K} \bigcap_{i \in K} \bigcap_{j \in K} \bigcap_{$$

### where

K is the episode number j is the time in seconds after the stact of a run m is the index for moving averages, m = 1, 2, 4, 8 W is the velocity in miles per hour  $\triangle$  jk are the wind weighting factors (see table below) K is a conversion constant, K = 88/60 i is the height of observation given in the following table:

1	Height (feet)	Wind weighting factor △ jk
1	25	. 050
2	50	. 950
3	75	. 030
4	100	. 035
5	125	. 030
6	150	. 045
7	175	. 050
8	200	. 040
9	250	. 065

p is a specified value or combination of its as given in the following table:

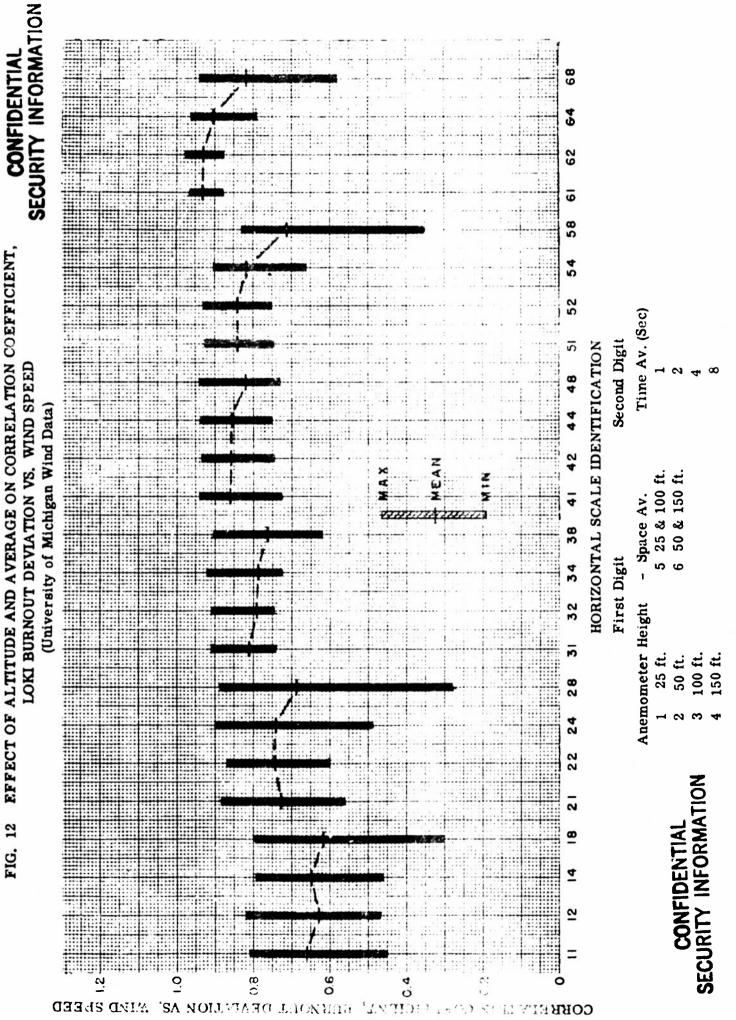
$$W_{p_1} = W_{i_1}$$
 $W_{p_4} = W_{i_6}$ 
 $W_{p_2} = W_{i_2}$ 
 $W_{p_5} = \frac{W_{i_1} + W_{i_4}}{2}$ 
 $W_{p_5} = \frac{W_{i_2} + W_{i_6}}{2}$ 

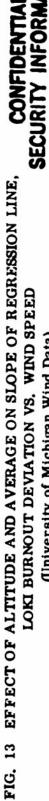
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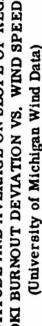
Results are summarized in Figs, 12 through 14, which show the range and average of the three significant parameters plotted as vertical bars and each of the combinations of anemometer height and time average. Runs 17, 19, 34, and 35 have been excluded in certain cases where missing data have resulted in small sample size and resulting range extremes. The unweighted arithmetical mean is shown on each bar. Fig. 12 shows the effect of progressive increase of time average on correlation coefficient of burnout deviation vs. wind speed for progressively increasing anemometer heights from 25 to 150 feet and also for time average 25 to 100 foot winds and 50-150-foot winds. Similar progressive sequences are shown for the regression line slope in Fig. 13 and 90% confidence limits in Fig. 14.

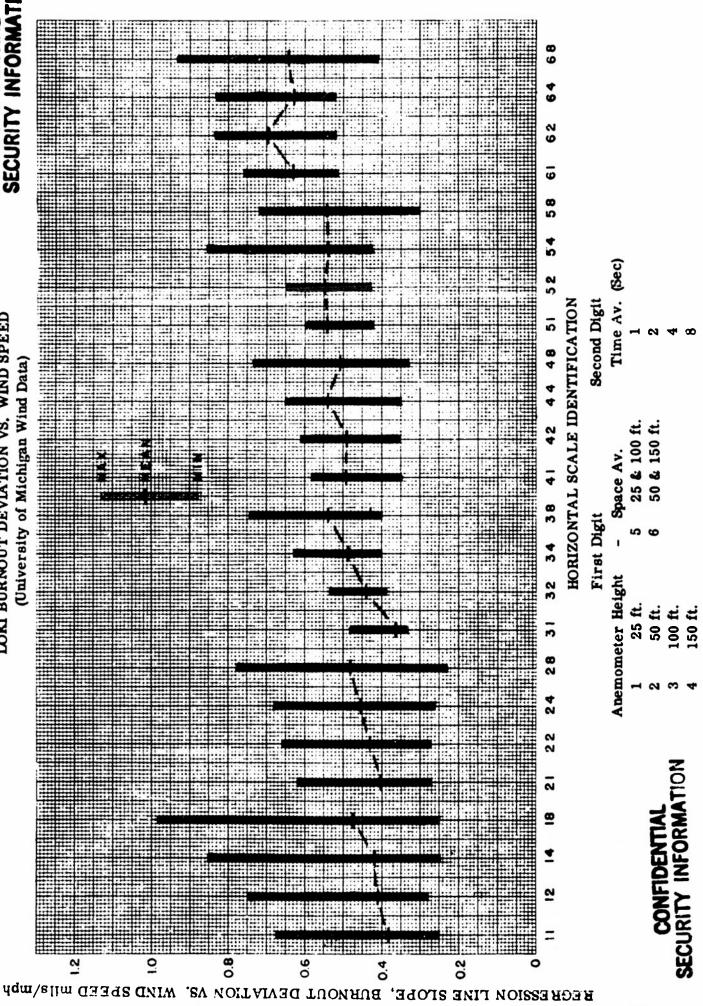
It is evident that the 2-second average offers improved correlation and reduced spread among runs under the 1 and 4-second averages. Further, a pronounced degradation is observed with the 8-second average.

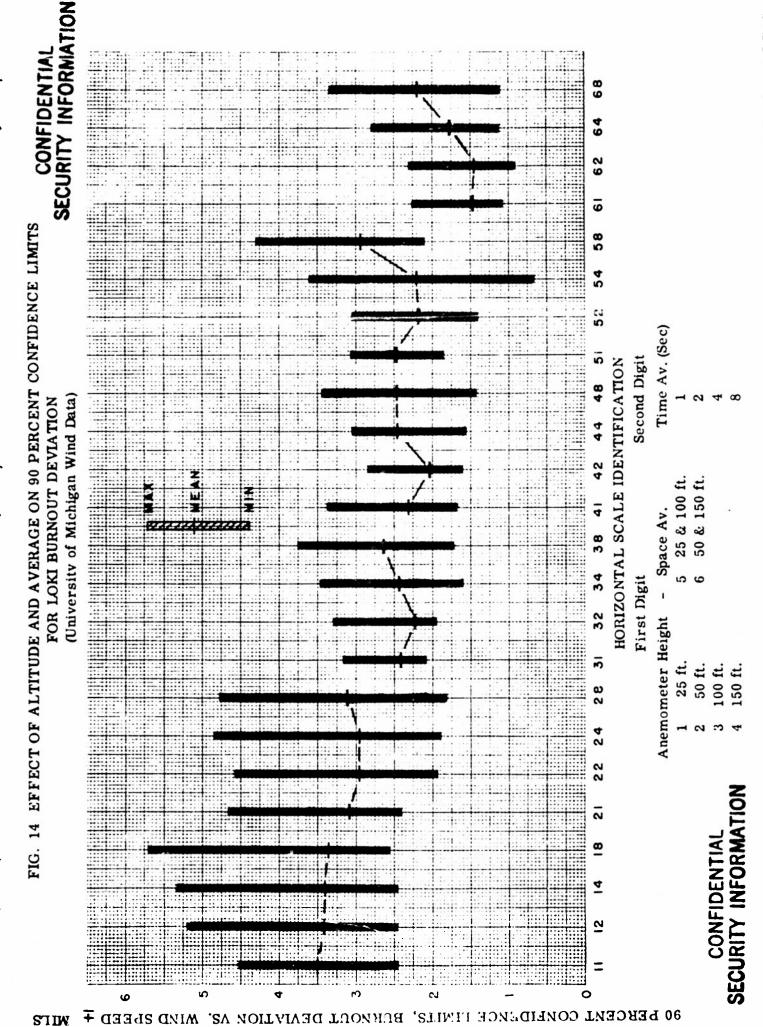
In progressing upward in altitude a marked improvement occurs in going from 50 to 100 feet with subsequent slight improvement at 150 feet. Best results are observed in the 50-150 foot mean wind sequences. However, the improvement over the 100-foot wind would hardly warrant the use of 2 anemometers in a wind correction computing system.











-18-

The present results are in substantial agreement with those obtained in the preliminary analysis of Ref. 1, and indicate the best choice of altitude and smoothing that would apply to vertical trajectories under the condition that would obtain at the Michigan test site in winter storm conditions.

For an anemometer height of 100 feet and 2-second average, the correction for wind effect in the first 250 feet of a vertical trajectory (about 50% of the total) could be expressed by the relation:

 $-\delta_{c} = 0.48W+4$ 

where  $\delta$  = burnout deviation correction, mils

w' = 100 foot 2-second average wind velocity, mph,

the 90% confidence limits would be + 2 mils.

Supplementary data obtained from hot wire surveys up to 1000 feet at White Sands
Proving Ground and El Mirage Airport, using equipment described in Ref. 3, is now
being analyzed and should permit the establishment of a tentative wind correction correction equation for the entire boost phase.

The effects of horizontal separation between the anemometer and launcher, elevation angle of launching, terrain and weather conditions, must also be considered in the design of a tactical system. These will be investigated in the Signal Corps sponsored project which is now being conducted by North American Instruments, Inc.

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### APPENDIX

# STATISTICAL RESULTS OF LOKI BURNOUT DEVIATION VS. WIND VELOCITY COMPARISON

The tables which follow present the results of the statistical computations described above, p. 15, and are direct photographs of the original IBM records. The accuracy is no better than 3 figures, the additional figures were allowed to appear as a matter of convenience in machine operation.

The identification code for the various columns as given on p. 15 are repeated below:

p = height of observation code number

m = index for moving average, seconds

k - episode number

N = number of observations

J = mean burnout deviation, mils, for episode

A = mean wind velocity, mph, for episode

b = regression line slope, mils/mph

 $8_{v90} = 90\%$  confidence limits, mils

r = correlation coefficient

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